

IN THE CLAIMS:

The claims are reproduced below for the convenience of the Examiner. No amendments are being made.

Claim 1 (Original): A gait pattern generating device of a walking robot for generating a gait pattern from a desired ZMP trajectory using ZMP preview information, wherein a driving quantity of the center of gravity in one moment is determined on the basis of a fed-back motion state of the center of gravity in the moment and a previewed or planned future ZMP trajectory, so as to generate a walking motion in real time.

Claim 2 (Original): The gait pattern generating device of a walking robot using ZMP preview information according to Claim 1, wherein the walking robot is a bipedal walking robot.

Claim 3(Original): The gait pattern generating device of a walking robot using ZMP preview information according to Claim 1 or 2, wherein the previewed or planned future ZMP trajectory is corrected based on a detailed dynamical model of the robot in addition to a basic model using a table-cart model.